

**AMENDMENTS TO THE CLAIMS:**

This listing of claims will replace all prior versions and listings of claims in the application:

1. (Currently amended) An articulated robot comprising:

a plurality of joint arms connected to one another,

wherein each of the joint arms are is connected to an adjacent joint arm ~~one-~~  
another-via a first rotating shaft,

~~wherein at least one location and via a second rotating shaft at least one-~~  
~~location, the~~ an axis of the a second rotating shaft at one end of one of the plurality of  
joint arms being is inclined relative to the an axis of a the first rotating shaft at the other  
end of the one of the plurality of the joint arms, and

wherein each rotating shaft is provided with a motor for driving the rotating shaft  
and with a speed-reducing mechanism, and

wherein the plurality of joint arms include a joint arm having two motors for  
driving the first and second rotating shafts and a joint arm with no motor, wherein the  
joint arm with no motor is adjacently connected to the joint arm having two motors.

2. (Original) The articulated robot according to claim 1, wherein each of the  
first and second rotating shafts has a hollow part through which a cable or the like  
necessary for controlling the articulated robot is passed.

3. (Withdrawn) The articulated robot according to claim 1 or 2, wherein each joint arm is provided with a motor for driving either the first or the second rotating shaft connected thereto.

4. (Cancelled)

5. (Withdrawn) The articulated robot according to claim 1, wherein at least one joint arm is provided with a brake device independent of the motor, the brake device being disposed in parallel with the motor relative to gears constituting a speed reducing mechanism.

6. (Withdrawn) The articulated robot according to claim 2, wherein at least one joint arm is provided with a brake device independent of the motor, the brake device being disposed in parallel with the motor relative to gears constituting a speed reducing mechanism.

7. (Withdrawn) The articulated robot according to claim 3, wherein at least one joint arm is provided with a brake device independent of the motor, the brake device being disposed in parallel with the motor relative to gears constituting a speed reducing mechanism.

8. (Withdrawn) The articulated robot according to claim 4, wherein at least one joint arm is provided with a brake device independent of the motor, the brake

device being disposed in parallel with the motor relative to gears constituting a speed reducing mechanism.